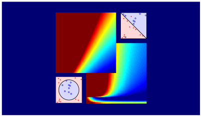
Machine Learning Foundations
(機器學習基石)



Lecture 12: Nonlinear Transformation

Hsuan-Tien Lin (林軒田)

htlin@csie.ntu.edu.tw

Department of Computer Science
& Information Engineering

National Taiwan University
(國立台灣大學資訊工程系)

Roadmap

1. When Can Machines Learn?
2. Why Can Machines Learn?
3. **How** Can Machines Learn?

   Lecture 11: Linear Models for Classification

   binary classification via **(logistic) regression**;
   multiclass via **OVA/OVO decomposition**

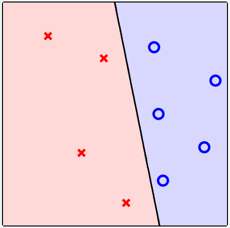
   Lecture 12: Nonlinear Transformation

   - Quadratic Hypotheses
   - Nonlinear Transform
   - Price of Nonlinear Transform
   - Structured Hypothesis Sets

4. How Can Machines Learn Better?

Linear Hypotheses

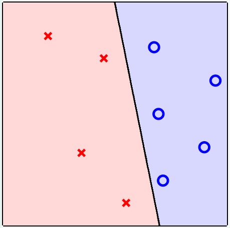
up to now: linear hypotheses



- visually: **'line'-like** boundary

Linear Hypotheses

up to now: linear hypotheses



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- mathematically: linear scores $s = \mathbf{w}^T\mathbf{x}$

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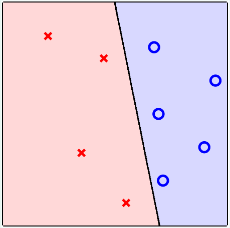
up to now: linear hypotheses



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but limited . . .

- theoretically: d_{VC} **under control :-)**

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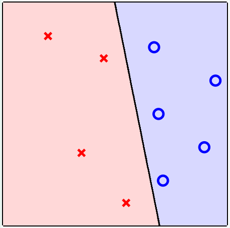

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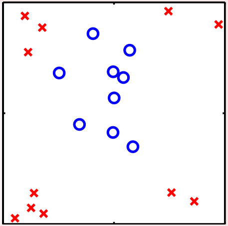

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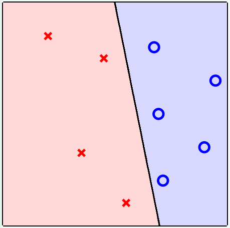
- practically: on some $\mathcal{D}$, **large** E_{in} for every line **:-(**

Linear Hypotheses

up to now: linear hypotheses



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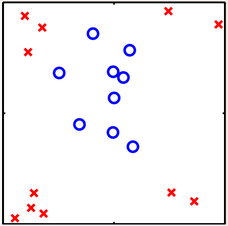

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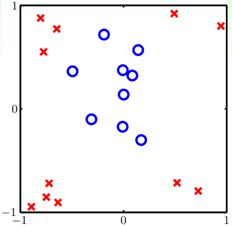
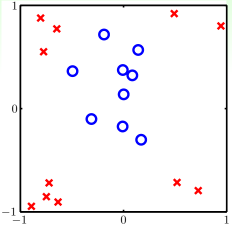
how to **break the limit** of linear hypotheses

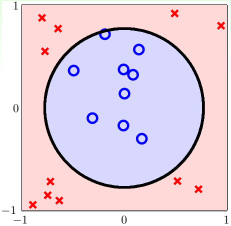
Circular Separable



- $\mathcal{D}$ not linear separable

Circular Separable

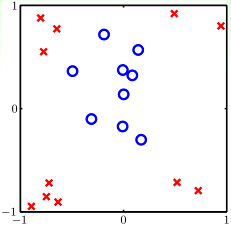


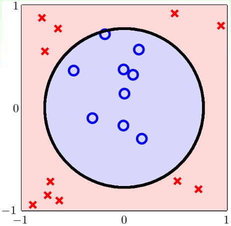


- $\mathcal{D}$ not linear separable
- but **circular separable** by a circle of radius $\sqrt{0.6}$ centered at origin:

$$h_{\text{SEP}}(\mathbf{x}) = \text{sign}\left(-x_1^2 - x_2^2 + 0.6\right)$$

Circular Separable





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re-derive **Circular**-PLA, **Circular**-Regression, blahblah . . . all over again? **:-)**

Circular Separable and Linear Separable

$$h(\mathbf{x}) = \text{sign}\left(0.6 \quad -1 \cdot x_1^2 \quad -1 \cdot x_2^2 \right)$$

Circular Separable and Linear Separable

$$h(\mathbf{x}) = \text{sign}\left(\underbrace{0.6}_{\tilde{w}_0} \cdot \underbrace{1}_{z_0} + \underbrace{(-1)}_{\tilde{w}_1} \cdot \underbrace{x_1^2}_{z_1} + \underbrace{(-1)}_{\tilde{w}_2} \cdot \underbrace{x_2^2}_{z_2} \right)$$

$$=$$

Circular Separable and Linear Separable

$$
\begin{aligned}
h(\mathbf{x}) &= \text{sign}\left(\underbrace{0.6}_{\tilde{w}_0} \cdot \underbrace{1}_{z_0} + \underbrace{(-1)}_{\tilde{w}_1} \cdot \underbrace{x_1^2}_{z_1} + \underbrace{(-1)}_{\tilde{w}_2} \cdot \underbrace{x_2^2}_{z_2} \right) \\
&= \text{sign}\left(\tilde{\mathbf{w}}^T \mathbf{z} \right)
\end{aligned}
$$

Circular Separable and Linear Separable

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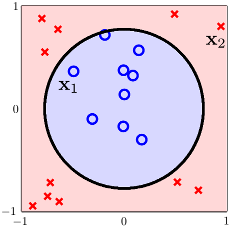
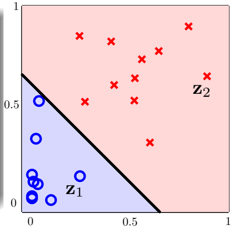
$$= \text{sign}\left(\tilde{\mathbf{w}}^T \mathbf{z}\right)$$



- $\{(\mathbf{x}_n, y_n)\}$ circular separable $\Longrightarrow \{(\mathbf{z}_n, y_n)\}$ linear separable



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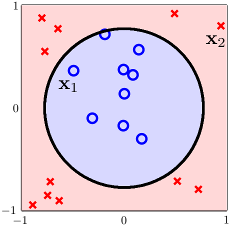

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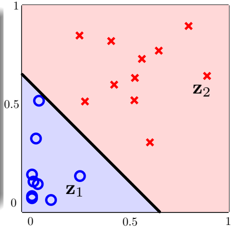
- $\mathbf{x} \in \mathcal{X} \overset{\mathbf{\Phi}}{\longmapsto} \mathbf{z} \in \mathcal{Z}$: **(nonlinear) feature transform $\mathbf{\Phi}$**



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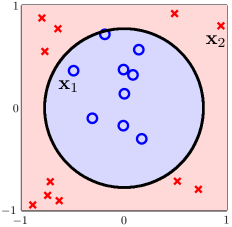

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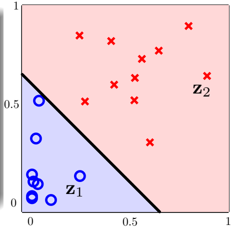

circular separable in $\mathcal{X} \Longrightarrow$ linear separable in $\mathcal{Z}$

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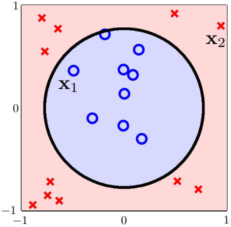

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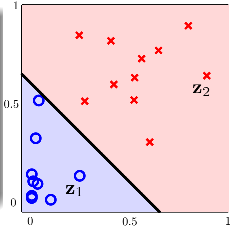

circular separable in $\mathcal{X} \Longrightarrow$ linear separable in $\mathcal{Z}$

vice versa?

Linear Hypotheses in $\mathcal{Z}$-Space

$$(z_0, z_1, z_2) = \mathbf{z} = \mathbf{\Phi}(\mathbf{x}) = (1, x_1^2, x_2^2)$$

$$h(\mathbf{x}) = \tilde{h}(\mathbf{z}) = \text{sign}\left(\tilde{\mathbf{w}}^T \mathbf{\Phi}(\mathbf{x})\right) = \text{sign}\left(\tilde{w}_0 + \tilde{w}_1 x_1^2 + \tilde{w}_2 x_2^2\right)$$

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- $(0.6, -1, -1)$: circle ($\circ$ inside)

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lines in $\mathcal{Z}$-space
$\Longleftrightarrow$ **special** quadratic curves in $\mathcal{X}$-space

General Quadratic Hypothesis Set

a 'bigger' $\mathcal{Z}$-space with $\mathbf{\Phi}_2(\mathbf{x}) = (1, x_1, x_2, x_1^2, x_1 x_2, x_2^2)$

perceptrons in $\mathcal{Z}$-space $\Longleftrightarrow$ quadratic hypotheses in $\mathcal{X}$-space

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$$\mathcal{H}_{\mathbf{\Phi}_2} = \left\{ h(\mathbf{x})\colon\ h(\mathbf{x}) = \tilde{h}(\mathbf{\Phi}_2(\mathbf{x})) \text{ for some linear } \tilde{h} \text{ on } \mathcal{Z} \right\}$$

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- can implement **all possible quadratic curve boundaries**: circle, ellipse, **rotated** ellipse, hyperbola, parabola, ...

ellipse $2(x_1 + x_2 - 3)^2 + (x_1 - x_2 - 4)^2 = 1$

$\Longleftarrow \tilde{\mathbf{w}}^T =$

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$\Longleftarrow \tilde{\mathbf{w}}^T = [33, -20, -4, 3, 2, 3]$

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  $\Longleftarrow \tilde{\mathbf{w}}^T = [33, -20, -4, 3, 2, 3]$
- include **lines and constants as degenerate cases**

General Quadratic Hypothesis Set

a 'bigger' $\mathcal{Z}$-space with $\mathbf{\Phi}_2(\mathbf{x}) = (1, x_1, x_2, x_1^2, x_1 x_2, x_2^2)$

perceptrons in $\mathcal{Z}$-space $\iff$ quadratic hypotheses in $\mathcal{X}$-space

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next: **learn** a good quadratic hypothesis g

Fun Time

Using the transform $\mathbf{\Phi}_2(\mathbf{x}) = (1, x_1, x_2, x_1^2, x_1 x_2, x_2^2)$, which of the following weights $\tilde{\mathbf{w}}^T$ in the $\mathcal{Z}$-space implements the parabola $2x_1^2 + x_2 = 1$?

1. $[-1, 2, 1, 0, 0, 0]$
2. $[0, 2, 1, 0, -1, 0]$
3. $[-1, 0, 1, 2, 0, 0]$
4. $[-1, 2, 0, 0, 0, 1]$

Fun Time

Using the transform $\mathbf{\Phi}_2(\mathbf{x}) = (1, x_1, x_2, x_1^2, x_1 x_2, x_2^2)$, which of the following weights $\tilde{\mathbf{w}}^T$ in the $\mathcal{Z}$-space implements the parabola $2x_1^2 + x_2 = 1$?

1. $[-1, 2, 1, 0, 0, 0]$
2. $[0, 2, 1, 0, -1, 0]$
3. $[-1, 0, 1, 2, 0, 0]$
4. $[-1, 2, 0, 0, 0, 1]$

Reference Answer: 3

Too simple, uh? :-) Flexibility to implement arbitrary quadratic curves opens new possibilities for minimizing E_{in}!

Good Quadratic Hypothesis

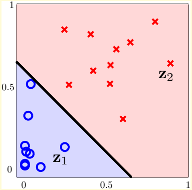
$\mathcal{Z}$-space		$\mathcal{X}$-space
perceptrons	$\Longleftrightarrow$	quadratic hypotheses

Good Quadratic Hypothesis

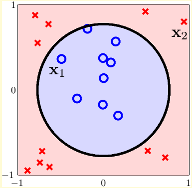
$\mathcal{Z}$-space		$\mathcal{X}$-space
perceptrons	$\Longleftrightarrow$	quadratic hypotheses
good perceptron	$\Longleftrightarrow$	**good quadratic hypothesis**

Good Quadratic Hypothesis

$\mathcal{Z}$-space		$\mathcal{X}$-space
perceptrons	$\Longleftrightarrow$	quadratic hypotheses
good perceptron	$\Longleftrightarrow$	**good quadratic hypothesis**
separating perceptron	$\Longleftrightarrow$	**separating quadratic hypothesis**

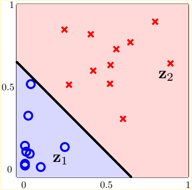


$\Longleftrightarrow$



Good Quadratic Hypothesis

$\mathcal{Z}$-space		$\mathcal{X}$-space
perceptrons	$\Longleftrightarrow$	quadratic hypotheses
good perceptron	$\Longleftrightarrow$	**good quadratic hypothesis**
separating perceptron	$\Longleftrightarrow$	**separating quadratic hypothesis**



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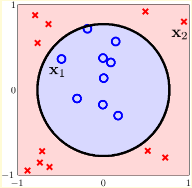
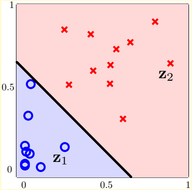


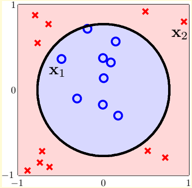
- want: get **good perceptron** in $\mathcal{Z}$-space

Good Quadratic Hypothesis

$\mathcal{Z}$-space		$\mathcal{X}$-space
perceptrons	$\Longleftrightarrow$	quadratic hypotheses
good perceptron	$\Longleftrightarrow$	**good quadratic hypothesis**
separating perceptron	$\Longleftrightarrow$	**separating quadratic hypothesis**



$\Longleftrightarrow$



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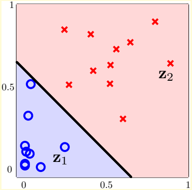

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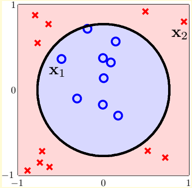

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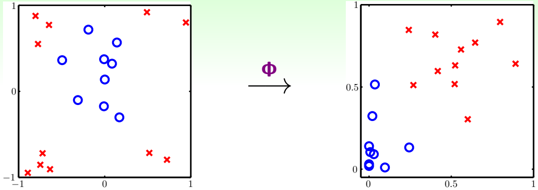
todo: get **good perceptron** in $\mathcal{Z}$-space with data $\{(\mathbf{z}_n = \mathbf{\Phi}_2(\mathbf{x}_n), y_n)\}$

The Nonlinear Transform Steps



1. transform original data $\{(\mathbf{x}_n, y_n)\}$ to $\{(\mathbf{z}_n = \mathbf{\Phi}(\mathbf{x}_n), y_n)\}$ by $\mathbf{\Phi}$

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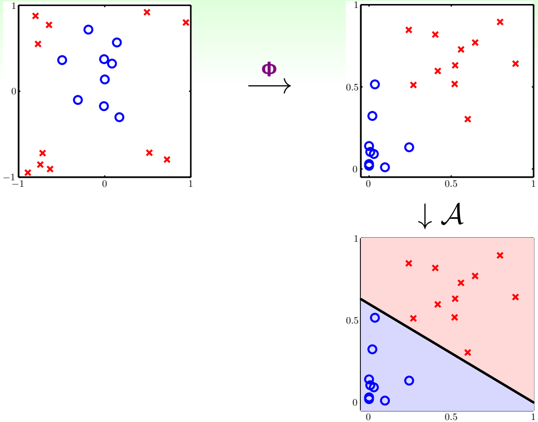

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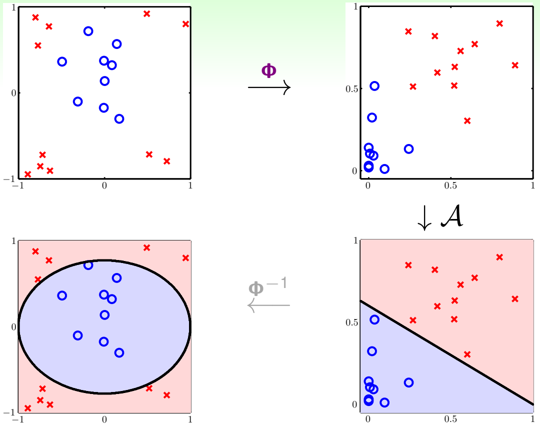

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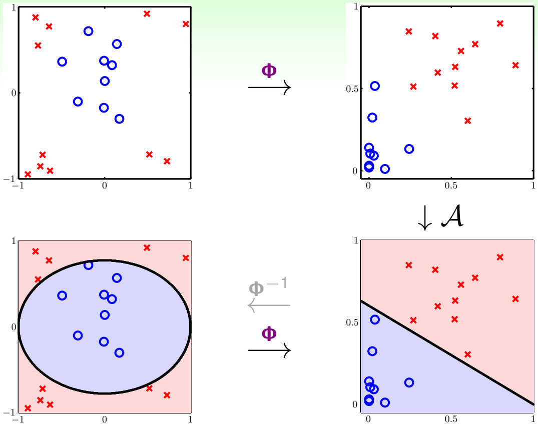

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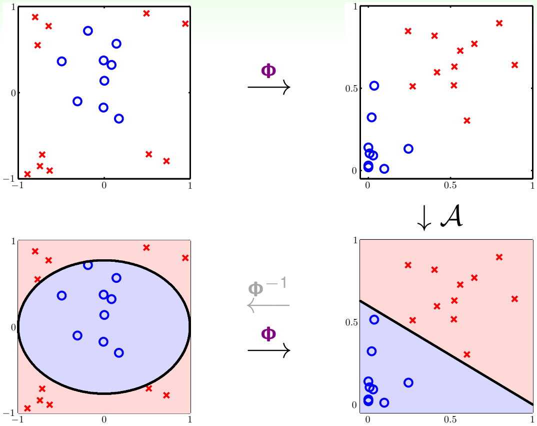
Nonlinear Model via Nonlinear Φ + Linear Models



two choices:

- feature transform Φ

Pandora's box :-):

can now freely do **quadratic PLA, quadratic regression, cubic regression, . . ., polynomial regression**

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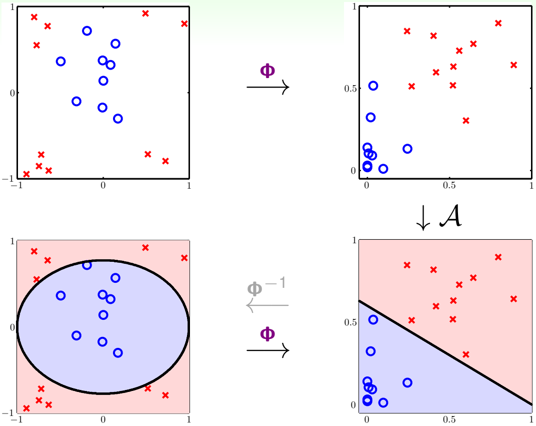

two choices:

- feature transform $\mathbf{\Phi}$
- linear model $\mathcal{A}$, **not just binary classification**

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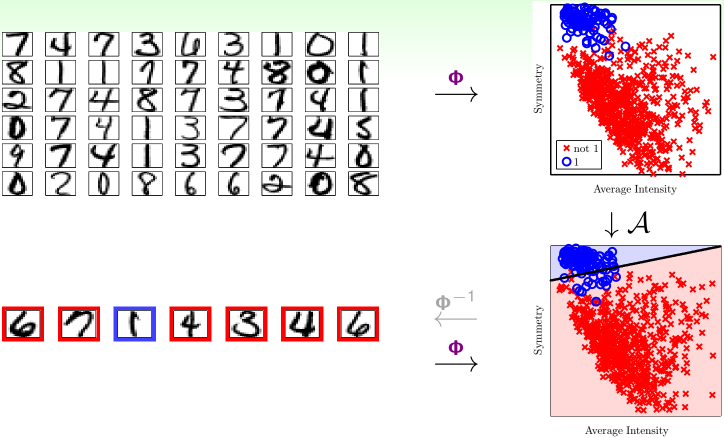
Feature Transform Φ



not new, not just polynomial:

raw (pixels) $\xrightarrow{\text{domain knowledge}}$ **concrete (intensity, symmetry)**

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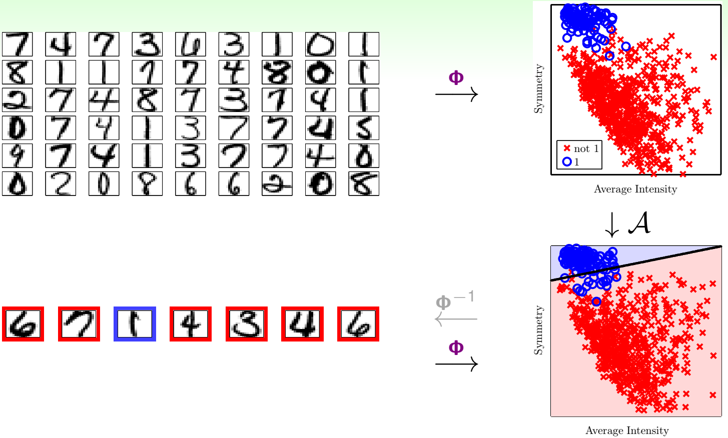

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the force, too good to be true? :-)

Fun Time

Consider the quadratic transform $\mathbf{\Phi}_2(\mathbf{x})$ for $\mathbf{x} \in \mathbb{R}^d$ instead of in $\mathbb{R}^2$. The transform should include all different quadratic, linear, and constant terms formed by $(x_1, x_2, \ldots, x_d)$. What is the number of dimensions of $\mathbf{z} = \mathbf{\Phi}_2(\mathbf{x})$?

1. d
2. $\frac{d^2}{2} + \frac{3d}{2} + 1$
3. $d^2 + d + 1$
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Reference Answer: 2

Number of different quadratic terms is $\binom{d}{2} + d$;
number of different linear terms is d;
number of different constant term is 1.

Computation/Storage Price

Q-th order polynomial transform: $\boldsymbol{\Phi}_Q(\mathbf{x}) = \Big($ 1,

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Q large $\Longrightarrow$ **difficult to compute/store**

Model Complexity Price

Q-th order polynomial transform: $\mathbf{\Phi}_Q(\mathbf{x}) = \Big(1, x_1, x_2, \ldots, x_d, x_1^2, x_1 x_2, \ldots, x_d^2, \ldots, x_1^Q, x_1^{Q-1} x_2, \ldots, x_d^Q \Big)$

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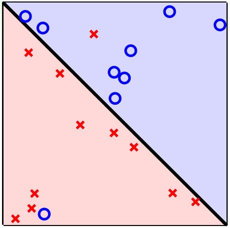
$\Longrightarrow$ any $\tilde{d} + 2$ inputs not shattered in $\mathcal{X}$

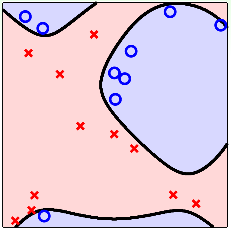
Q large $\Longrightarrow$ **large** d_{VC}

Generalization Issue



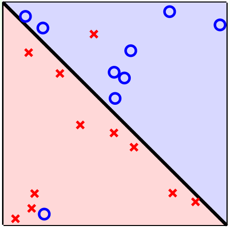
$\mathbf{\Phi}_1$ (original $\mathbf{x}$)

which one do you prefer? :-)



$\mathbf{\Phi}_4$

Generalization Issue



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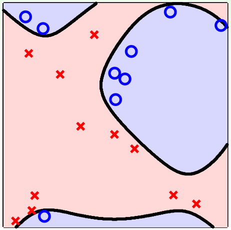

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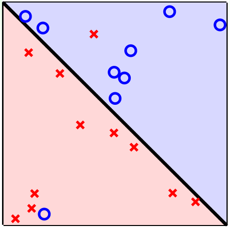

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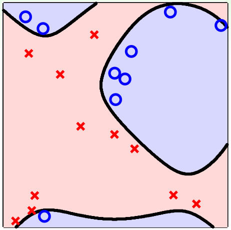

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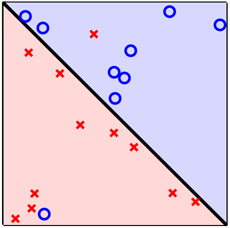

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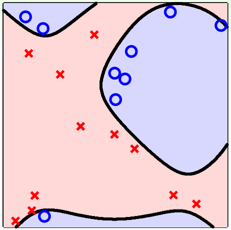

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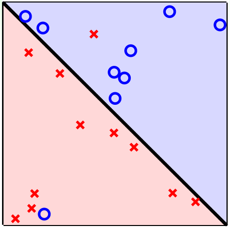
Generalization Issue



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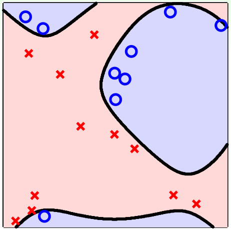

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$\tilde{d}$ (Q)	1	2
higher	:-(	**:-D**
lower	**:-D**	:-(

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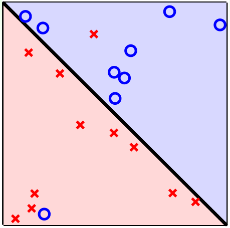

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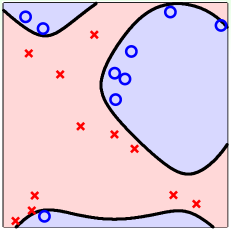

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how to pick Q? **visually**, maybe?

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Visualize $\mathcal{X} = \mathbb{R}^2$

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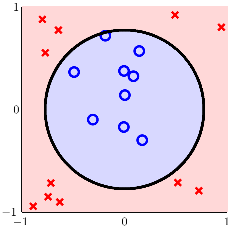

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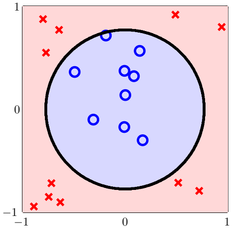

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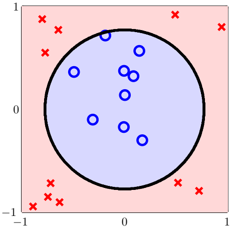

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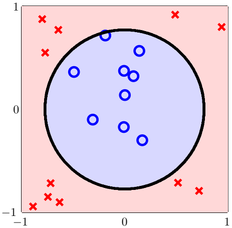
- or even better $\mathbf{z} = \left(\text{sign}(0.6 - x_1^2 - x_2^2)\right)$?



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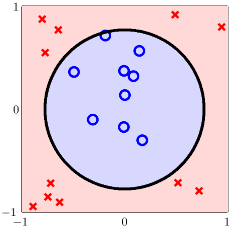
Visualize $\mathcal{X} = \mathbb{R}^2$

- full $\mathbf{\Phi}_2$: $\mathbf{z} = (1, x_1, x_2, x_1^2, x_1x_2, x_2^2)$, $d_{\text{VC}} = 6$
- or $\mathbf{z} = (1, x_1^2, x_2^2)$, $d_{\text{VC}} = 3$, **after visualizing**?
- or better $\mathbf{z} = (1, x_1^2 + x_2^2)$, $d_{\text{VC}} = 2$?
- or even better $\mathbf{z} = \left(\text{sign}(0.6 - x_1^2 - x_2^2)\right)$?

—careful about **your brain's 'model complexity'**



Danger of Visual Choices

first of all, can you really 'visualize' when $\mathcal{X} = \mathbb{R}^{10}$? **(well, I can't :-))**

Visualize $\mathcal{X} = \mathbb{R}^2$

- full $\boldsymbol{\Phi}_2$: $\mathbf{z} = (1, x_1, x_2, x_1^2, x_1x_2, x_2^2)$, $d_{\text{VC}} = 6$
- or $\mathbf{z} = (1, x_1^2, x_2^2)$, $d_{\text{VC}} = 3$, **after visualizing**?
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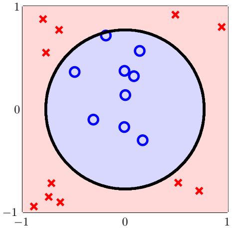

for VC-safety, $\boldsymbol{\Phi}$ shall be decided **without 'peeking'** data

Fun Time

Consider the Q-th order polynomial transform $\mathbf{\Phi}_Q(\mathbf{x})$ for $\mathbf{x} \in \mathbb{R}^2$. Recall that $\tilde{d} = \binom{Q+2}{2} - 1$. When $Q = 50$, what is the value of $\tilde{d}$?

1. 1126
2. 1325
3. 2651
4. 6211

Fun Time

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1. 1126
2. 1325
3. 2651
4. 6211

Reference Answer: ②

It's just a simple calculation, but shows you how $\tilde{d}$ becomes hundreds of times of $d = 2$ after the transform.

Polynomial Transform Revisited

$$\boldsymbol{\Phi}_0(\mathbf{x}) = \Big(1\Big), \boldsymbol{\Phi}_1(\mathbf{x}) = \Big(\boldsymbol{\Phi}_0(\mathbf{x}), \qquad x_1, x_2, \ldots, x_d\Big)$$

Polynomial Transform Revisited

$$\Phi_0(\mathbf{x}) = \left(1\right), \Phi_1(\mathbf{x}) = \left(\Phi_0(\mathbf{x}), \quad x_1, x_2, \ldots, x_d\right)$$

$$\Phi_2(\mathbf{x}) = \left(\Phi_1(\mathbf{x}), \quad x_1^2, x_1 x_2, \ldots, x_d^2\right)$$

Polynomial Transform Revisited

$$\begin{aligned}
\Phi_0(\mathbf{x}) = \left(1\right), \Phi_1(\mathbf{x}) &= \left(\Phi_0(\mathbf{x}), \quad x_1, x_2, \ldots, x_d\right) \\
\Phi_2(\mathbf{x}) &= \left(\Phi_1(\mathbf{x}), \quad x_1^2, x_1 x_2, \ldots, x_d^2\right) \\
\Phi_3(\mathbf{x}) &= \left(\Phi_2(\mathbf{x}), \quad x_1^3, x_1^2 x_2, \ldots, x_d^3\right) \\
& \quad \ldots \quad \ldots
\end{aligned}$$

Polynomial Transform Revisited

$$
\begin{aligned}
\mathbf{\Phi}_0(\mathbf{x}) = \left(1\right), \mathbf{\Phi}_1(\mathbf{x}) &= \left(\mathbf{\Phi}_0(\mathbf{x}), \qquad x_1, x_2, \ldots, x_d\right) \\
\mathbf{\Phi}_2(\mathbf{x}) &= \left(\mathbf{\Phi}_1(\mathbf{x}), \qquad x_1^2, x_1 x_2, \ldots, x_d^2\right) \\
\mathbf{\Phi}_3(\mathbf{x}) &= \left(\mathbf{\Phi}_2(\mathbf{x}), \qquad x_1^3, x_1^2 x_2, \ldots, x_d^3\right) \\
&\ldots \qquad \ldots \\
\mathbf{\Phi}_Q(\mathbf{x}) &= \left(\mathbf{\Phi}_{Q-1}(\mathbf{x}), \qquad x_1^Q, x_1^{Q-1} x_2, \ldots, x_d^Q\right)
\end{aligned}
$$

Polynomial Transform Revisited

$$
\begin{aligned}
\Phi_0(\mathbf{x}) = (1),\ \Phi_1(\mathbf{x}) &= (\Phi_0(\mathbf{x}), && x_1, x_2, \ldots, x_d) \\
\Phi_2(\mathbf{x}) &= (\Phi_1(\mathbf{x}), && x_1^2, x_1 x_2, \ldots, x_d^2) \\
\Phi_3(\mathbf{x}) &= (\Phi_2(\mathbf{x}), && x_1^3, x_1^2 x_2, \ldots, x_d^3) \\
& \ldots && \ldots \\
\Phi_Q(\mathbf{x}) &= (\Phi_{Q-1}(\mathbf{x}), && x_1^Q, x_1^{Q-1} x_2, \ldots, x_d^Q)
\end{aligned}
$$

$$
\mathcal{H}_{\Phi_0} \subset \mathcal{H}_{\Phi_1} \subset \mathcal{H}_{\Phi_2} \subset \mathcal{H}_{\Phi_3} \subset \ldots \subset \mathcal{H}_{\Phi_Q}
$$

Polynomial Transform Revisited

$$\begin{aligned}
\Phi_0(\mathbf{x}) = \left(1\right), \Phi_1(\mathbf{x}) &= \left(\Phi_0(\mathbf{x}), \quad x_1, x_2, \ldots, x_d\right) \\
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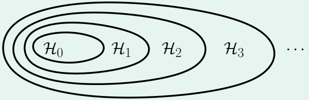
&\ldots \quad \ldots \\
\Phi_Q(\mathbf{x}) &= \left(\Phi_{Q-1}(\mathbf{x}), \quad x_1^Q, x_1^{Q-1} x_2, \ldots, x_d^Q\right)
\end{aligned}$$

$$\begin{array}{ccccccccccc}
\mathcal{H}_{\Phi_0} & \subset & \mathcal{H}_{\Phi_1} & \subset & \mathcal{H}_{\Phi_2} & \subset & \mathcal{H}_{\Phi_3} & \subset & \ldots & \subset & \mathcal{H}_{\Phi_Q} \\
\| & & \| & & \| & & \| & & & & \| \\
\mathcal{H}_0 & & \mathcal{H}_1 & & \mathcal{H}_2 & & \mathcal{H}_3 & & \ldots & & \mathcal{H}_Q
\end{array}$$



Polynomial Transform Revisited

$$\begin{aligned}
\Phi_0(\mathbf{x}) = (1), \Phi_1(\mathbf{x}) &= (\Phi_0(\mathbf{x}), \quad x_1, x_2, \ldots, x_d) \\
\Phi_2(\mathbf{x}) &= (\Phi_1(\mathbf{x}), \quad x_1^2, x_1 x_2, \ldots, x_d^2) \\
\Phi_3(\mathbf{x}) &= (\Phi_2(\mathbf{x}), \quad x_1^3, x_1^2 x_2, \ldots, x_d^3) \\
&\ldots \quad \ldots \\
\Phi_Q(\mathbf{x}) &= (\Phi_{Q-1}(\mathbf{x}), \quad x_1^Q, x_1^{Q-1} x_2, \ldots, x_d^Q)
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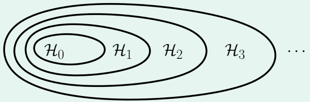
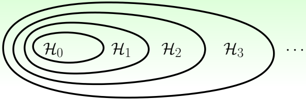
$$\begin{array}{ccccccccccc}
\mathcal{H}_{\Phi_0} & \subset & \mathcal{H}_{\Phi_1} & \subset & \mathcal{H}_{\Phi_2} & \subset & \mathcal{H}_{\Phi_3} & \subset & \ldots & \subset & \mathcal{H}_{\Phi_Q} \\
\| & & \| & & \| & & \| & & & & \| \\
\mathcal{H}_0 & & \mathcal{H}_1 & & \mathcal{H}_2 & & \mathcal{H}_3 & & \ldots & & \mathcal{H}_Q
\end{array}$$



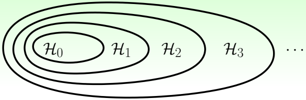
structure: **nested $\mathcal{H}_i$**

Structured Hypothesis Sets



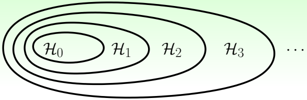
$$\mathcal{H}_0 \quad \subset \quad \mathcal{H}_1 \quad \subset \quad \mathcal{H}_2 \quad \subset \quad \mathcal{H}_3 \quad \subset \quad \ldots$$

Structured Hypothesis Sets



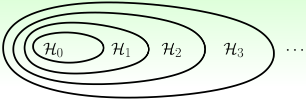
$\mathcal{H}_0$	$\subset$	$\mathcal{H}_1$	$\subset$	$\mathcal{H}_2$	$\subset$	$\mathcal{H}_3$	$\subset$	$\ldots$
$d_{\text{VC}}(\mathcal{H}_0)$		$d_{\text{VC}}(\mathcal{H}_1)$		$d_{\text{VC}}(\mathcal{H}_2)$		$d_{\text{VC}}(\mathcal{H}_3)$		$\ldots$

Structured Hypothesis Sets



$$\begin{array}{ccccccccc} \mathcal{H}_0 & \subset & \mathcal{H}_1 & \subset & \mathcal{H}_2 & \subset & \mathcal{H}_3 & \subset & \ldots \\ d_{\text{VC}}(\mathcal{H}_0) & \leq & d_{\text{VC}}(\mathcal{H}_1) & \leq & d_{\text{VC}}(\mathcal{H}_2) & \leq & d_{\text{VC}}(\mathcal{H}_3) & \leq & \ldots \end{array}$$

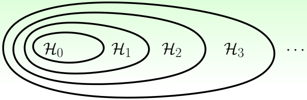
Structured Hypothesis Sets



Let $g_i = \text{argmin}_{h \in \mathcal{H}_i} E_{\text{in}}(h)$:

$$
\begin{array}{ccccccccc}
\mathcal{H}_0 & \subset & \mathcal{H}_1 & \subset & \mathcal{H}_2 & \subset & \mathcal{H}_3 & \subset & \ldots \\
d_{\text{VC}}(\mathcal{H}_0) & \leq & d_{\text{VC}}(\mathcal{H}_1) & \leq & d_{\text{VC}}(\mathcal{H}_2) & \leq & d_{\text{VC}}(\mathcal{H}_3) & \leq & \ldots \\
E_{\text{in}}(g_0) & & E_{\text{in}}(g_1) & & E_{\text{in}}(g_2) & & E_{\text{in}}(g_3) & & \ldots
\end{array}
$$

Structured Hypothesis Sets



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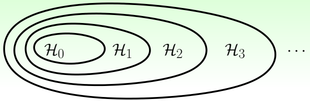
E_{\text{in}}(g_0) & \geq & E_{\text{in}}(g_1) & \geq & E_{\text{in}}(g_2) & \geq & E_{\text{in}}(g_3) & \geq & \ldots
\end{array}
$$

Structured Hypothesis Sets



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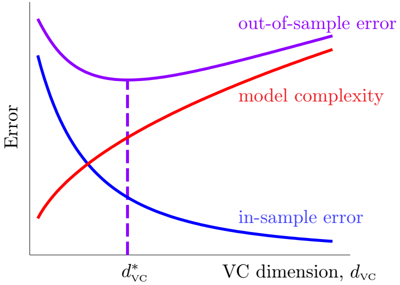
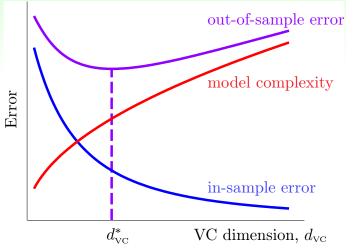
$$\begin{array}{ccccccccc} \mathcal{H}_0 & \subset & \mathcal{H}_1 & \subset & \mathcal{H}_2 & \subset & \mathcal{H}_3 & \subset & \cdots \\ d_{\text{VC}}(\mathcal{H}_0) & \le & d_{\text{VC}}(\mathcal{H}_1) & \le & d_{\text{VC}}(\mathcal{H}_2) & \le & d_{\text{VC}}(\mathcal{H}_3) & \le & \cdots \\ E_{\text{in}}(g_0) & \ge & E_{\text{in}}(g_1) & \ge & E_{\text{in}}(g_2) & \ge & E_{\text{in}}(g_3) & \ge & \cdots \end{array}$$



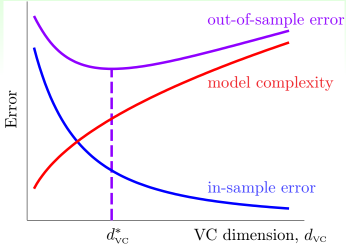
use $\mathcal{H}_{1126}$ won't be good! :-(

Linear Model First



- tempting sin: use $\mathcal{H}_{1126}$, low $E_{\text{in}}(g_{1126})$ to fool your boss

Linear Model First



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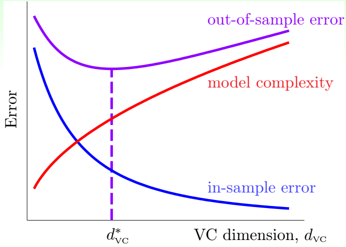
  —**really? :-(a dangerous path of no return**

Linear Model First



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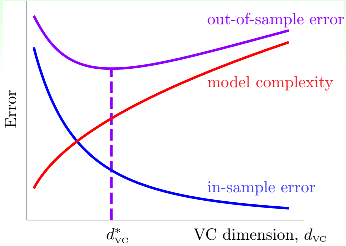
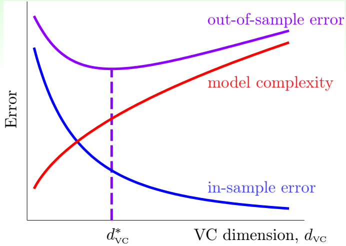
- safe route: $\mathcal{H}_1$ first

Linear Model First



- tempting sin: use $\mathcal{H}_{1126}$, low $E_{\text{in}}(g_{1126})$ to fool your boss —**really? :-(a dangerous path of no return**
- safe route: $\mathcal{H}_1$ first
  - if $E_{\text{in}}(g_1)$ good enough, **live happily thereafter :-)**

Linear Model First



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- safe route: $\mathcal{H}_1$ first
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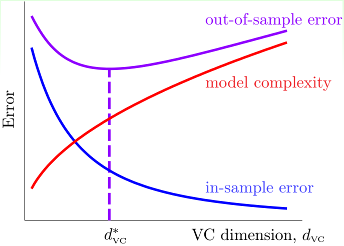
  - otherwise, move right of the curve **with nothing lost except 'wasted' computation**

Linear Model First



- tempting sin: use $\mathcal{H}_{1126}$, low $E_{\text{in}}(g_{1126})$ to fool your boss —**really? :-(a dangerous path of no return**
- safe route: $\mathcal{H}_1$ first
  - if $E_{\text{in}}(g_1)$ good enough, **live happily thereafter :-)**
  - otherwise, move right of the curve **with nothing lost except 'wasted' computation**

linear model first:
simple, efficient, **safe**, **and workable!**

Fun Time

Consider two hypothesis sets, $\mathcal{H}_1$ and $\mathcal{H}_{1126}$, where $\mathcal{H}_1 \subset \mathcal{H}_{1126}$. Which of the following relationship between $d_{\text{VC}}(\mathcal{H}_1)$ and $d_{\text{VC}}(\mathcal{H}_{1126})$ is not possible?

1. $d_{\text{VC}}(\mathcal{H}_1) = d_{\text{VC}}(\mathcal{H}_{1126})$
2. $d_{\text{VC}}(\mathcal{H}_1) \neq d_{\text{VC}}(\mathcal{H}_{1126})$
3. $d_{\text{VC}}(\mathcal{H}_1) < d_{\text{VC}}(\mathcal{H}_{1126})$
4. $d_{\text{VC}}(\mathcal{H}_1) > d_{\text{VC}}(\mathcal{H}_{1126})$

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3. $d_{\mathrm{VC}}(\mathcal{H}_1) < d_{\mathrm{VC}}(\mathcal{H}_{1126})$
4. $d_{\mathrm{VC}}(\mathcal{H}_1) > d_{\mathrm{VC}}(\mathcal{H}_{1126})$

Reference Answer: 4

Every input combination that $\mathcal{H}_1$ shatters can be shattered by $\mathcal{H}_{1126}$, so d_{VC} cannot decrease.

Summary

1. When Can Machines Learn?
2. Why Can Machines Learn?
3. **How** Can Machines Learn?

Lecture 11: Linear Models for Classification

Lecture 12: Nonlinear Transformation

- Quadratic Hypotheses

  linear hypotheses on quadratic-transformed data
- Nonlinear Transform

  happy linear modeling after $\mathcal{Z} = \mathbf{\Phi}(\mathcal{X})$
- Price of Nonlinear Transform

  computation/storage/[model complexity]
- Structured Hypothesis Sets

  linear/simpler model first

- **next: dark side of the force :-)**

4. How Can Machines Learn Better?